

A Thesis Title

by

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Submitted to the Dept. of Earth, Atmospheric and Planetary Sciences
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Abstract

In this thesis, I designed and implemented a compiler which performs optimizations that reduce the number of low-level floating point operations necessary for a specific task; this involves the optimization of chains of floating point operations as well as the implementation of a “fixed” point data type that allows some floating point operations to simulated with integer arithmetic. The source language of the compiler is a subset of C, and the destination language is assembly language for a micro-floating point CPU. An instruction-level simulator of the CPU was written to allow testing of the code. A series of test pieces of codes was compiled, both with and without optimization, to determine how effective these optimizations were.

Thesis Supervisor: Glenn R. Flierl

Title: Professor of Oceanography

Acknowledgments

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Contents

1	Introduction	13
1.1	The Aerocene Project	13
2	Methods	15
2.1	Interpolation	15
2.2	Integration Scheme	15
2.3	Timestep	16

List of Figures

List of Tables

Chapter 1

Introduction

1.1 The Aerocene Project

Chapter 2

Methods

2.1 Interpolation

Both the kinematic and dynamic models require an interpolation scheme to produce values for atmospheric variables in between the gridded values provided by GFS. Linear interpolation is the standard choice for trajectory models [Bowman et al., 2013]. For both models, linear interpolation was used in three dimensions (latitude, longitude, and time). In the kinematic model, u and v components of wind speed were interpolated, while in the dynamic model, geopotential height was interpolated.

2.2 Integration Scheme

The numerical scheme chosen was a second-order Runge-Kutta method with a long track record in trajectory modeling [Petterssen, 1940]. The velocity at a given timestep is taken to be the average of the velocity at the initial position and the velocity at the first-guess position after one timestep.

The first guess position $\vec{P}'(t + \Delta t)$ is

$$\vec{P}'(t + \Delta t) = \vec{P}(t) + \vec{V}(\vec{P}, t)\Delta t \quad (2.1)$$

and the final position $\vec{P}(t + \Delta t)$ is

$$\vec{P}(t + \Delta t) = \vec{P}(t) + \frac{1}{2} \left[\vec{V}(\vec{P}, t) + \vec{V}(\vec{P}', t + \Delta t) \right] \Delta t \quad (2.2)$$

where \vec{P} is a position vector with latitude and longitude components, and \vec{V} a velocity vector with u and v wind speeds [Draxler and Hess, 1997]. This integration method is used by HYSPLIT and a number of other trajectory models, including FLEXPART, LAGRANTO, and STILT [Stein et al., 2015] [Bowman et al., 2013]. For trajectories calculated from interpolated gridded wind velocities, higher order integration schemes do not add precision [Draxler and Hess, 1997].

2.3 Timestep

The timestep for integration was three minutes, with the timestep throughout the trajectory. To save computation, HYSPLIT uses a dynamic timestep, varying from one minute to one hour, computed to satisfy

$$U_{max}[\text{grid-units min}^{-1}] \Delta t[\text{min}] < 0.75[\text{grid-units}] \quad (2.3)$$

[Draxler and Hess, 1997]. This ensures that the parcel does not blow past any grid squares during a single timestep, which maximizes the accuracy of the calculation.

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